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☐	L17	(5024920 | 5173382 | 5490103 | 5557564 | 5901829 | 6201488 | 6521838 | 6518503 | 6695663 | 6592418 | 5733819 | 6027554 | 6663326 | 6694847 | 6685863 | 4252414 | 4588518 | 4561746 | 4719331 | 5118090 | 5434926 | 5419740 | 5558196 | 5527940 | 5716481).pn.	47
☐	L16	motion pattern and L14	2
☐	L15	motion pattern and stor$3 and L14	0
☐	L14	freedom and L13	5
☐	L13	L11 and L12	6
☐	L12	L11 and gait or gate	931875
☐	L11	('6580969' |'6493606' |'6463356' |'6289265' |'6243623' |'5872893' |'5841258' |'5838130' |'5594644' |'EP 1136193A' |'EP 1103451A')!.ABPN1,NRPN,PN,TBAN,WKU.	18
☐	L10	('20030019671' |'20020138359' |'6591923' |'6458011')!.ABPN1,NRPN,PN,TBAN,WKU.	7
☐	L9	(legged robot or pet robot or humanoid near10 robot) motion and pattern	7
☐	L8	(legged robot or pet robot or humanoid near10 robot) motion and pattern and L7	0
☐	L7	(6252544 | 6493606 | 6243623 | 6289265 | 5673367 | 5355064 | 5455497 | 5325031 | 5357433 | 5594644 | 6580969 | 6718231 | 5504841 | 5842533 | 4621333 | 4633059 | 4987527 | 5937398 | 6064168 | 6429812 | 6584377 | 5259064 | 5349646 | 5946041 | 4540211 | 4762261 | 5273296 | 5616917 | 5627440 | 5794621 | 6059092 | 6059092 | 6068201 | 6456728 | 6505098 | 6711469 | 5402050 | 5525883 | 5841258 | 6463356 | 4614504 | 5040626 | 5343397 | 5369346 | 5378969 | 5644204 | 5672924 | 5838130 | 5872893 | 6229552).pn.	97
☐	L6	robot$6 and (walk$3 or biped or humanoid or two legged) and (inlina$6 or betn or tilt or deviat$5 or obliqu$5 or indirect$4 or change direction or slope or slant)	3172
☐	L5	('6711469' |'6697709' |'6567724' |'6505098' |'6493606' |'6480761' |'6330494' |'6289265' |'6243623')!.ABPN1,NRPN,PN,TBAN,WKU.	16
☐	L4	marc.xa. and legged and inclination	10
☐	L3	marc.xa. and legged and inclinaiton	0
☐	L2	robot and motion generation and time	42
☐	L1	robot and motion generation and time same sequential	0

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☐	L4	gait and robot$6 and (humanoid or biped or two legged) and (zmp or zero moment point) and (foot or feet) and trunk and control	26
☐	L3	actuator and L1	1
☐	L2	control and L1	2
☐	L1	6463356.pn.	2

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Key: **IEEE JNL** = IEEE Journal or Magazine, **IEE JNL** = IEE Journal or Magazine, **IEEE CNF** = IEEE Conference, **IEE CNF** = IEE Conference, **IEEE STD** = IEEE Standard

1. **Motion planning for humanoid robots under obstacle and dynamic balance constraints**
   Kuffner, J.; Nishiwaki, K.; Kagami, S.; Inaba, M.; Inoue, H.;
   Robotics and Automation, 2001. Proceedings 2001 ICRA. IEEE International Conference on
   Volume 1, 2001 Page(s):692 - 698 vol.1
   IEEE CNF

2. **Posture control for biped robot walk with foot toe and sole**
   Takahashi, T.; Kawamura, A.;
   Industrial Electronics Society, 2001. IECON '01. The 27th Annual Conference of the IEEE
   Volume 1, 29 Nov.-2 Dec. 2001 Page(s):329 - 334 vol.1
   IEEE CNF

3. **Posture control using foot toe and sole for biped walking robot "Ken"**
   Takahashi, T.; Kawamura, A.;
   Advanced Motion Control, 2002. 7th International Workshop on
   3-5 July 2002 Page(s):437 - 442
   IEEE CNF

4. **Humanoid walk control with feedforward dynamic pattern and feedback sensory reflection**
   Qiang Huang; Kejie Li; Nakamura, Y.;
   Computational Intelligence in Robotics and Automation, 2001. Proceedings 2001 IEEE International Symposium on
   29 July-1 Aug. 2001 Page(s):29 - 34
   IEEE CNF

5. **Humanoids walk with feedforward dynamic pattern and feedback sensory reflection**
   Qiang Huang; Nakamura, Y.; Inamura, T.;
   Robotics and Automation, 2001. Proceedings 2001 ICRA. IEEE International Conference on
   Volume 4, 2001 Page(s):4220 - 4225 vol.4
   IEEE CNF

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... When the Honda **robot** loses its balance and threatens to **fall**, ... If the **robot** leans too far over, the target **ZMP** control operates to prevent it from ...
world.honda.com/ASIMO/history/technology2.html - 14k - Apr 17, 2005 - Cached - Similar pages

Grizzle, Jessy W.: Biped Experiments (RABBIT)
... He would surely **fall down**. On our **robot**, if you push him backward, ... The **robot** is purposefully underactuated (no feet) so that the **ZMP** principle does ...
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... **posture** of a humanoid **robot** according to the force applied ... we can see that the **robot** does not. always **fall down** even if the **ZMP** is on the edge of ...
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[DOC] Dynamics Based Integration of Motion Adaptation for a Quadruped ...
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... It was shown that **ZMP**-based control is effective for controlling **posture** and ... the gait was greatly disturbed, even if Tekken didn't **fall down**. ...
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... It was shown that **ZMP**-based control is effective for controlling **posture** and low-
... if Tekken didn't **fall down**. Consequently, it was shown that method ...
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Biped Locomotion
... The **robot** is now correcting its **posture** while it is walking, ... The locomotion is successfully executed, and the **robot** does not **fall down**.
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... be given if the humanoid **robot** falls **down** in the same plane, that is,. **zmp**
... signals can only describe the simple "go – no go" or "**fall down** – ...
www.ais.fraunhofer.de/robocup/ HL2003/010_Robo-Erectus_Humanoid.pdf - Similar pages

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... Actual **robot posture**. Command (torque). Σ. +. -. Online stab. **ZMP** Approach: conclusions ... **fall**. • Cons:. • Requires a perfect knowledge of the **robot**'s ...
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... **ZMP**(Zero Momentum Point) [3], which guarantees. that **robot** does not **fall**.
By this method, strong ... show the time when the **robot fall down**. Although ...
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... A **legged robot** apparatus having a zero moment point (**ZMP**) comprising: ...
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